## CLAIMS:

What is claimed is:

- 1 1. A robot, the robot comprising:
- a barcode scanner with a scan path, wherein the
- 3 barcode scanner is affixed to the robot;
- 4 an attenuation surface affixed to the barcode
- 5 scanner, wherein the attenuation surface is located such
- 6 that at least one end of the scan path of the barcode
- 7 scanner is controlled by the attenuation surface;
- 8 a positional encoding device for determining the
- 9 location of the attenuation surface with respect to a
- 10 target associated with at least one storage cell.
- 1 2. The robot as recited in claim 1, wherein the
- 2 attenuation surface comprises a plurality of edges and
- 3 wherein at least one of the edges are beveled.
- 1 3. The robot as recited in claim 1, wherein the
- 2 attenuation surface is constructed from a material that
- 3 is formable into sharp edges.
- 1 4. The robot as recited in claim 1, wherein the
- 2 attenuation surface reflects light from a scanner
- 3 illumination source in a non-detrimental manner.
- 1 5. The robot as recited in claim 1, wherein the
- 2 attenuation surface controls one or more ends of the scan
- 3 path during movement of the robot parallel to the scan

- 4 path in order to determine a target position in a first
- 5 coordinate frame.
- 1 6. The robot as recited in claim 1, wherein the
- 2 movement of the barcode scanner substantially orthogonal
- 3 to the scan path will determine the target position
- 4 relative to positional data from the robot in a second
- 5 coordinate frame.
- 1 7. The robot as recited in claim 1, wherein the target
- 2 is a barcode.
- 1 8. The robot as recited in claim 1, wherein the
- 2 attenuation surface comprises a metal.
- 1 9. The robot as recited in claim 1, wherein the
- 2 attenuation surface is black anodized.
- 1 10. The robot as recited in claim 1, wherein the barcode
- 2 scanner is a laser scanner.
- 1 11. The robot as recited in claim 10, wherein the laser
- 2 scanner comprises:
- 3 a laser; and
- 4 a moveable reflecting surface which reflects light
- 5 from the laser to an object external to the laser
- 6 scanner.

- 1 12. A robot, the robot comprising:
- 2 a barcode scanner with a scan path, wherein the
- 3 barcode scanner is affixed to the robot;
- 4 a positional encoding device for determining the
- 5 location of the scan path with respect to a target
- 6 associated with at least one storage cells within a
- 7 storage library.
- 1 13. The robot as recited in claim 12, wherein the
- 2 movement of the barcode scanner substantially orthogonal
- 3 to the scan path determines the position relative to
- 4 positional data from the robot.
- 1 14. The robot as recited in claim 12, wherein the target
- 2 is a barcode.
- 1 15. A positional determination device, the device
- 2 comprising:
- a barcode scanner with a scan path affixed to a
- 4 moveable object;
- 5 an attenuation surface affixed to the barcode
- 6 scanner, wherein the attenuation surface is located such
- 7 that at least one end of the scan path is controlled by
- 8 the attenuation surface; and
- 9 a positional encoding device for determining the
- 10 location of the object with respect to an external
- 11 object.

- 1 16. A library storage system, the system comprising:
- a plurality of storage cells, wherein at least some
- 3 of the plurality of storage cells include a target;
- a robot for moving items to and from the storage
- 5 cells, wherein the robot includes a barcode scanner with
- 6 a scan path, an attenuation surface, wherein the
- 7 attenuation surface is located such that at least one end
- 8 of the scan path is controlled by the attenuation
- 9 surface, and a positional encoding device for determining
- 10 the location of the attenuation surface with respect to
- 11 the target.
- 1 17. The library storage system as recited in claim 16,
- 2 wherein at least one of the edges of the attenuation
- 3 surface is beveled.
- 1 18. The library storage system as recited in claim 16,
- 2 wherein the attenuation surface is constructed from a
- 3 material that is formable into sharp edges.
- 1 19. The library storage system as recited in claim 16,
- 2 wherein the attenuation surface is configured to reflect
- 3 a scanner illumination source in a non-detrimental
- 4 manner.
- 1 20. The library storage system as recited in claim 16,
- 2 wherein the attenuation surface controls at least one end
- 3 of the scan path during movement of he robot parallel to
- 4 the scan path to determine target position in a first
- 5 coordinate frame.

- 1 21. The library storage system as recited in claim 16,
- 2 wherein the movement of the barcode scanner substantially
- 3 orthogonal to the scan path determines the target
- 4 position relative to positional data from the robot in a
- 5 second coordinate frame.
- 1 22. The library storage system as recited in claim 16,
- 2 wherein the target is a barcode.
- 1 23. A method for determining the position of a robot
- 2 relative to a target, the method comprising:
- 3 translating a robot having a barcode scan engine
- 4 with a scan path having a scan path width controlled by
- 5 an attenuation surface in a direction substantially
- 6 parallel to the scan path;
- 7 determining a first parallel position at which the
- 8 target is first readable by the barcode scan engine; and
- 9 determining a second parallel position at which the
- 10 target is first becomes unreadable by the barcode scan
- 11 engine.
  - 1 24. The method as recited in claim 23, further
  - 2 comprising:
- determining the center of the target in the parallel
- 4 direction from the first and second parallel positions.
- 1 25. The method as recited in claim 24, wherein the step
- 2 of determining the center of the target in the parallel
- 3 direction comprises assigning a position halfway between

- 4 the first and second parallel positions as the center
- 5 position of the target in the parallel direction.
- 1 26. The method as recited in claim 23, further
- 2 comprising:
- 3 translating the robot in a direction substantially
- 4 perpendicular the scan path;
- 5 determining a first perpendicular position at which
- 6 the target first becomes readable to the barcode scanner;
- 7 and
- 8 determining a second perpendicular position at which
- 9 the target first becomes unreadable by the barcode
- 10 scanner.
- 1 27. The method as recited in claim 26, further
- 2 comprising:
- determining the center of the target in the
- 4 perpendicular direction from the first and second
- 5 perpendicular positions.
- 1 28. The method as recited in claim 27, wherein the step
- 2 of determining the center of the target in the
- 3 perpendicular direction comprises assigning the midpoint
- 4 between the first and second perpendicular positions as
- 5 the center of the target in the perpendicular direction.
- 1 29. A system for determining the position of a robot
- 2 relative to a target, the system comprising:
- 3 first means for translating a robot having a barcode
- 4 scan engine with a scan path having a scan path width

- 5 controlled by an attenuation surface in a direction
- 6 substantially parallel to the scan path;
- 7 second means for determining a first parallel
- 8 position at which the target is first readable by the
- 9 barcode scan engine; and
- third means for determining a second parallel
- 11 position at which the target is first becomes unreadable
- 12 by the barcode scan engine.
- 1 30. The system as recited in claim 29, further
- 2 comprising:
- 3 fourth means for determining the center of the
- 4 target in the parallel direction from the first and
- 5 second parallel positions.
- 1 31. The system as recited in claim 30, wherein the
- 2 fourth means comprises assigning a position halfway
- 3 between the first and second parallel positions as the
- 4 center position of the target in the parallel direction.
- 1 32. The system as recited in claim 29, further
- 2 comprising:
- 3 fourth means for translating the robot in a
- 4 direction substantially perpendicular the scan path;
- 5 fifth means for determining a first perpendicular
- 6 position at which the target first becomes readable to
- 7 the barcode scanner; and
- 8 sixth means for determining a second perpendicular
- 9 position at which the target first becomes unreadable by
- 10 the barcode scanner.

- 1 33. The system as recited in claim 32, further
- 2 comprising:
- 3 seventh means for determining the center of the
- 4 target in the perpendicular direction from the first and
- 5 second perpendicular positions.
- 1 34. The system as recited in claim 33, wherein the
- 2 seventh means comprises assigning the midpoint between
- 3 the first and second perpendicular positions as the
- 4 center of the target in the perpendicular direction.